

**I. Amendments to the Specification:**

Please replace the Abstract as follows: (A “version with markings” and a “clean version” are provided below)

**Version With Markings: ABSTRACT**

A robot hand equipped with a function of gently pinching an object to be held is provided. A may include a single degree of freedom joint for allowing bending or stretching is provided at a connecting portion between a distal phalange section [[7]] and a middle phalange section [[9]]. The robot hand may further include [[Then,]] a driving mechanism for causing this joint to make a rotating motion within a predetermined angular range is provided. This driving mechanism [[14]] is constituted by a motor [[15]] for driving the joint and a speed reducer[[ 17]]. The motor 15 is included in the middle phalange section 9 and generates a driving force for rotating the joint. The speed reducer 17 reduces a speed of the motor 15 and transmits the reduced speed to the joint. The joint and the driving mechanism [[14]] are configured so that the distal phalange section [[7]] is rotated relative to the middle phalange section [[9]] in two directions, namely, an inward direction and an outward direction within the predetermined angular range from a state where the distal phalange section [[7]] is arranged in a straight line with the middle phalange section.

**Clean Version: ABSTRACT**

A robot hand equipped with a function of gently pinching an object may include a single degree of freedom joint for allowing bending or stretching at a connecting portion between a distal phalange section and a middle phalange section. The robot hand may further include a driving mechanism for causing this joint to make a rotating motion within a predetermined angular range. This driving mechanism is constituted by a motor and a speed reducer. The joint and the driving mechanism are configured so that the distal phalange section is rotated relative to the middle phalange section in two directions, namely, an inward direction and an outward direction within the predetermined angular range from a state where the distal phalange section is arranged in a straight line with the middle phalange section.